Fig. 1

Fig. 2

Fig. 3

Pixel Coordinates
From Look-Up Table
of Correspondences

$(x_l(n), y_l(n))$ $(x_r(n), y_r(n))$

42   43

40 Left camera image

41 Right camera image

44 Defining of measurement windows in the area surrounding the coordinates in the left and right image

45

46

47 Determination of quality via comparison of measurement windows (e.g., via correlation)
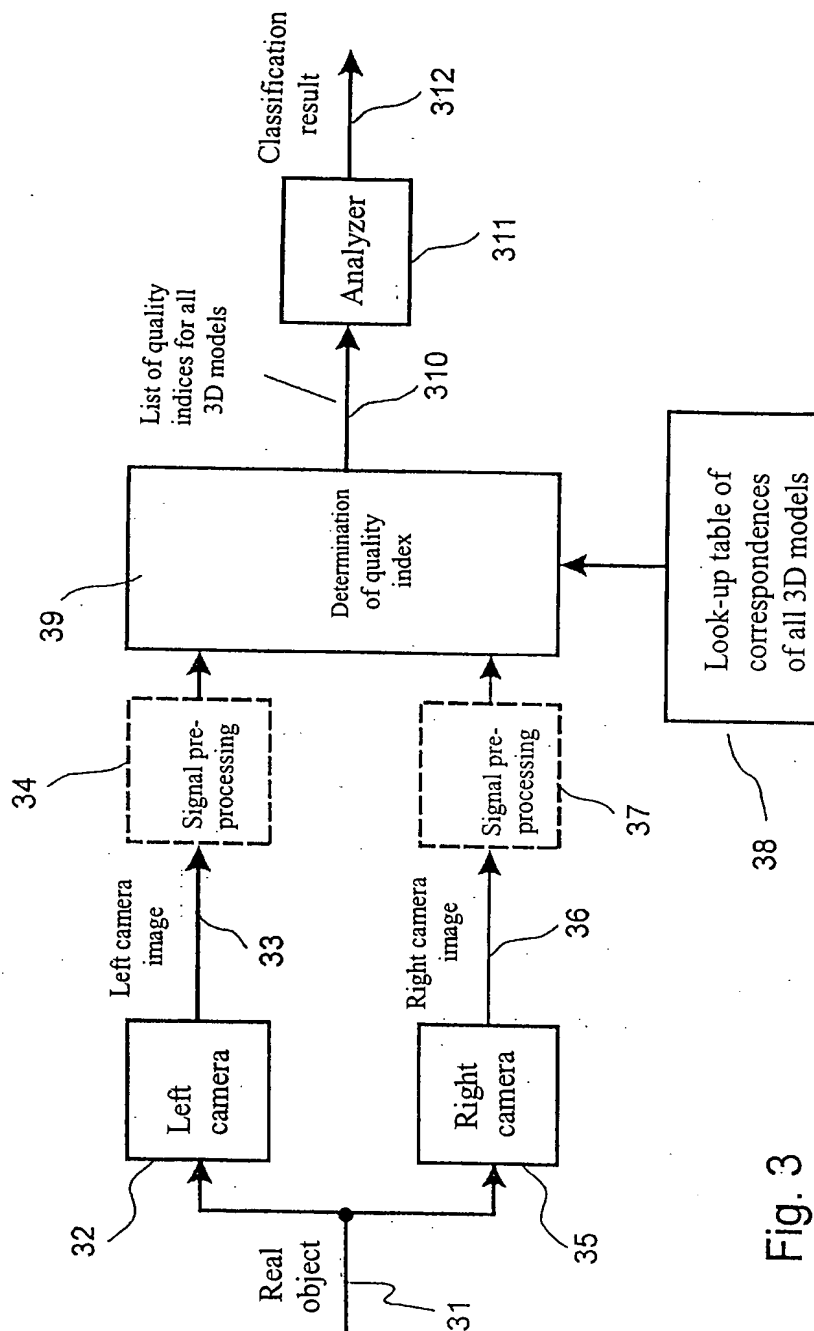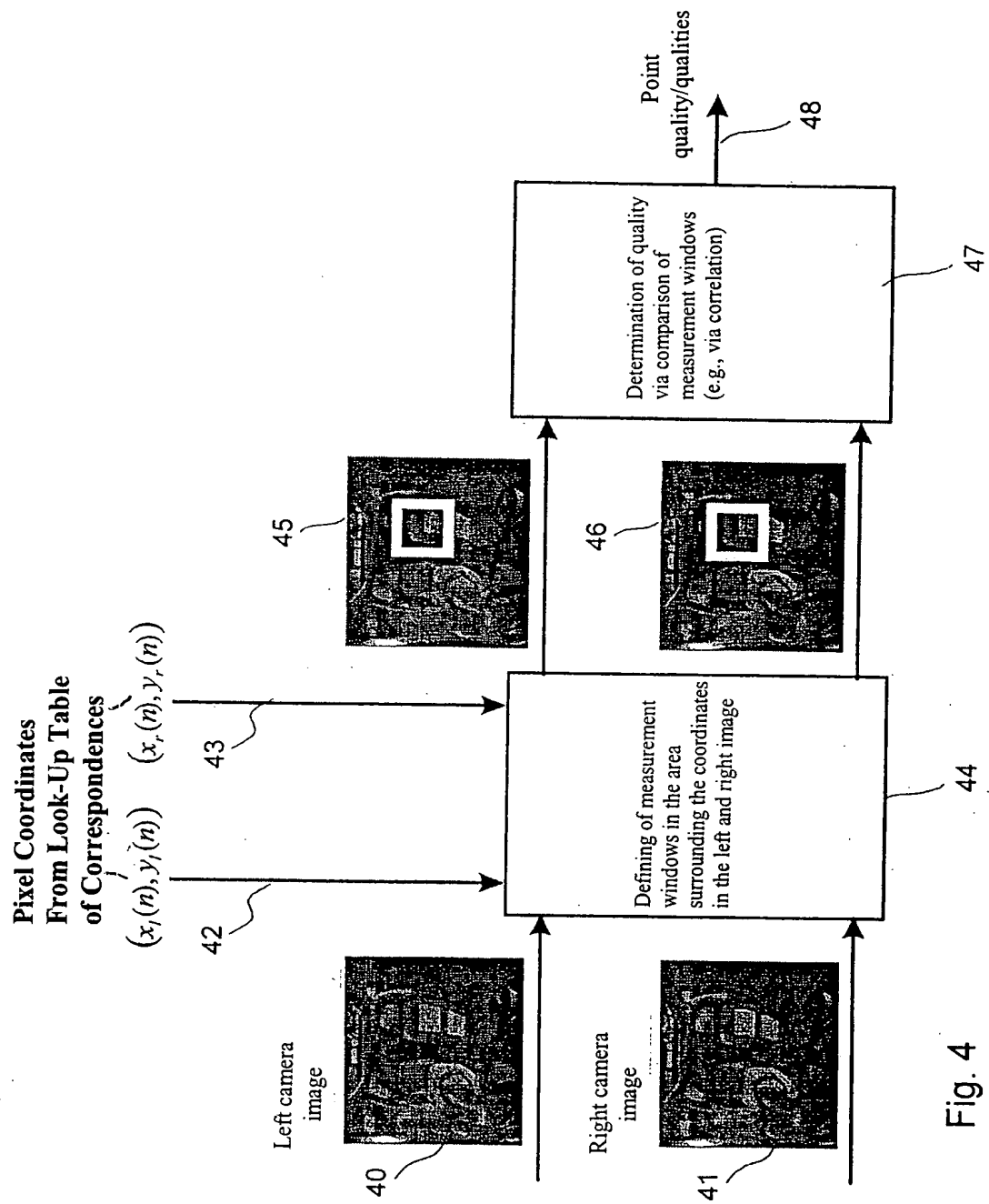
48 Point quality/qualities

Fig. 4
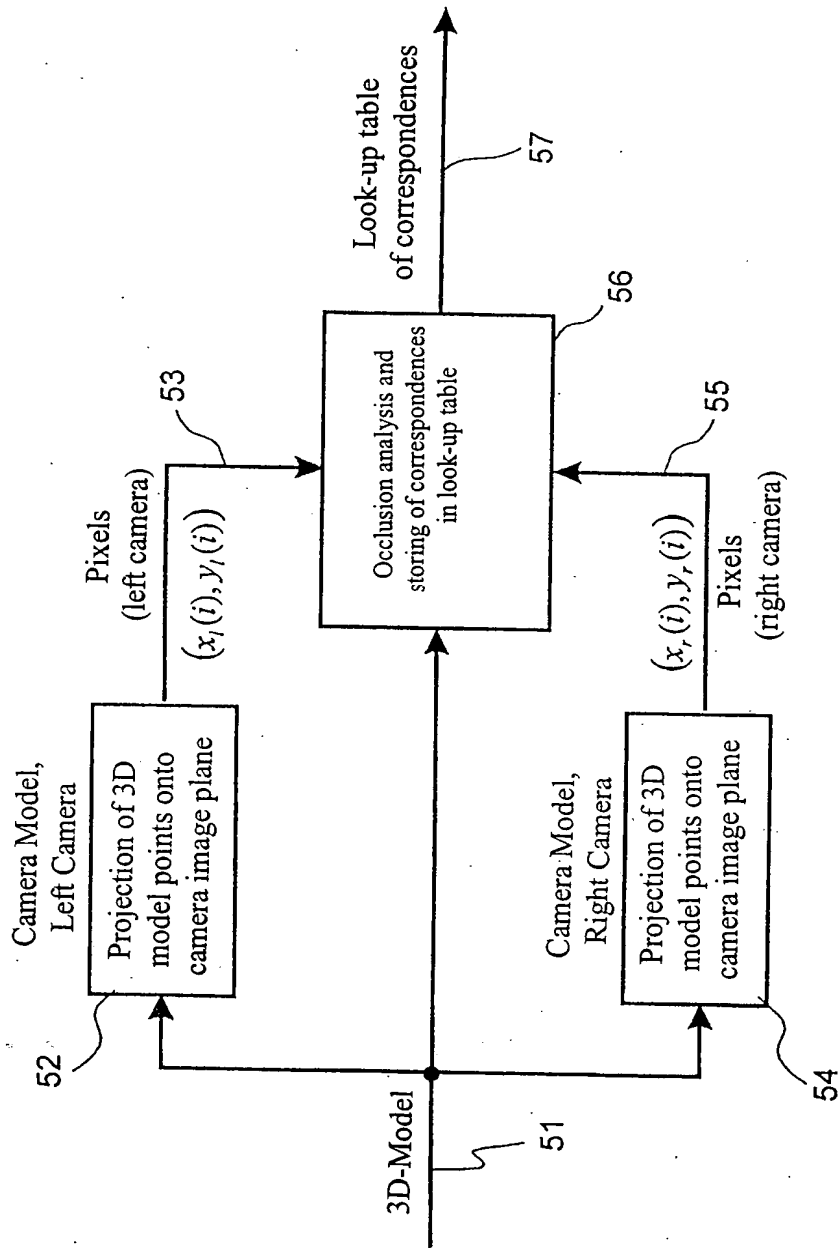
Fig. 5

Look-up table of correspondences for 3D model number k

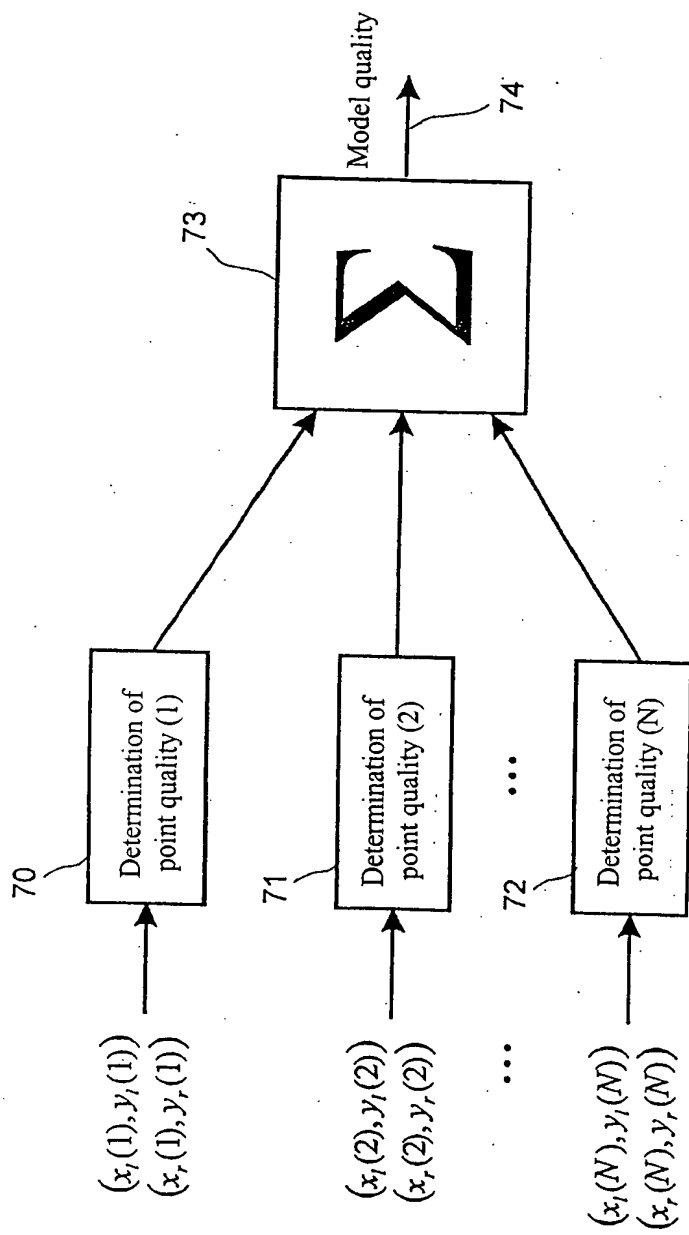| Point index	3D object point	Pixel, left camera	Pixel, right camera
1	$(x_o(1), y_o(1), z_o(1))$	$(x_l(1), y_l(1))$	$(x_r(1), y_r(1))$
2	$(x_o(2), y_o(2), z_o(2))$	$(x_l(2), y_l(2))$	$(x_r(2), y_r(2))$
3	...	...	...

Fig. 6

$(x_l(1), y_l(1))$
$(x_r(1), y_r(1))$

Determination of point quality (1) 70

$(x_l(2), y_l(2))$
$(x_r(2), y_r(2))$

Determination of point quality (2) 71

$(x_l(N), y_l(N))$
$(x_r(N), y_r(N))$

Determination of point quality (N) 72

$\sum$ 73

Model quality 74

Fig. 7